Amendments to the Claims:

      This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

      1-13. (Canceled).

      14. (Currently Amended) [[The]] A method as recited in Claim 13 for guiding a motor vehicle, comprising:

      forming a single evaluation quantity from a plurality of input quantities that represent a traffic situation;

      determining a plurality of dynamically changeable parameters based on the single evaluation quantity; and

      providing control variables for guiding the motor vehicle as a function of the plurality of input quantities that represent a traffic situation and as a function of the dynamically changeable parameters;

      wherein:

      the plurality of input quantities include location data of located objects;

      the method is used to provide control variables for adaptive speed control of the vehicle;

      a parameter selected on the basis of the single evaluation quantity relates to a selection of a target object from a plurality of located objects;

      an object-specific evaluation quantity is formed for each of a plurality of located objects on the basis of location data for the corresponding object; [[,]] and

      wherein an object having the greatest object-specific evaluation quantity is selected as the target object.

      15. (Previously Presented) The method as recited in Claim 14, wherein the single evaluation quantity is monotonically dependent on a distance to a located object and on a relative speed of the located object.

16. (Previously Presented) The method as recited in Claim 14, wherein the single evaluation quantity is determined from the plurality of input quantities, on the basis of a multi-dimensional characteristic map.

17. (Previously Presented) The method as recited in Claim 16, wherein the characteristic map is divided into at least two zones that correspond to different ranges of object distance, and wherein the single evaluation quantity is calculated according to different functions depending on a particular zone of the characteristic map, and wherein the different functions merge at the border between the two zones.

18. (Currently Amended) The method as recited in Claim [[13]] 14, wherein at least one of the dynamically changeable parameters determined on the basis of the single evaluation quantity is a parameter that determines at least one of speed of changes and extent of changes in the control variable resulting from changes in the input quantities.

19. (Previously Presented) The method as recited in Claim 18, wherein the at least one of the dynamically changeable parameters determined on the basis of the single evaluation quantity is a filter parameter for filtering at least one of the input quantities.

20. (Currently Amended) A device for providing control variables for guiding a motor vehicle, comprising:

a control unit for receiving from sensors a plurality of input quantities representing a traffic situation, calculating the control variables from the plurality of input quantities, and outputting the control variables to control elements of at least one of a drive system and a brake system of the motor vehicle;

wherein:

the control unit is configured to: a) form a single evaluation quantity from the plurality of input quantities that represent the traffic situation; b) determine a plurality of dynamically changeable parameters based on the single evaluation quantity; and c) provide the control variables for guiding the motor vehicle as a function of the plurality of input quantities that represent a traffic situation and as a function of the dynamically changeable parameters; ~~and wherein~~

the plurality of input quantities include location data of located objects: ~~, and wherein~~

the ~~method is used to provide~~ control variables are provided for adaptive speed control of the vehicle; ~~and wherein~~

a parameter determined on the basis of the single evaluation quantity relates to a selection of a target object from a plurality of located objects;

an object-specific evaluation quantity is formed for each of a plurality of located objects on the basis of location data for the corresponding object; and

an object having the greatest object-specific evaluation quantity if selected as the target object.

21. (New) A device for guiding a motor vehicle, comprising:

a control unit configured to:

form a single evaluation quantity from a plurality of input quantities that represent a traffic situation;

determine a plurality of dynamically changeable parameters based on the single evaluation quantity; and

provide control variables for guiding the motor vehicle as a function of the plurality of input quantities that represent a traffic situation and as a function of the dynamically changeable parameters;

wherein:

the plurality of input quantities include location data of located objects;

the control variables are provided for adaptive speed control of the vehicle;

a parameter selected on the basis of the single evaluation quantity relates to a selection of a target object from a plurality of located objects;

an object-specific evaluation quantity is formed for each of a plurality of located objects on the basis of location data for the corresponding object; and

an object having the greatest object-specific evaluation quantity is selected as the target object.